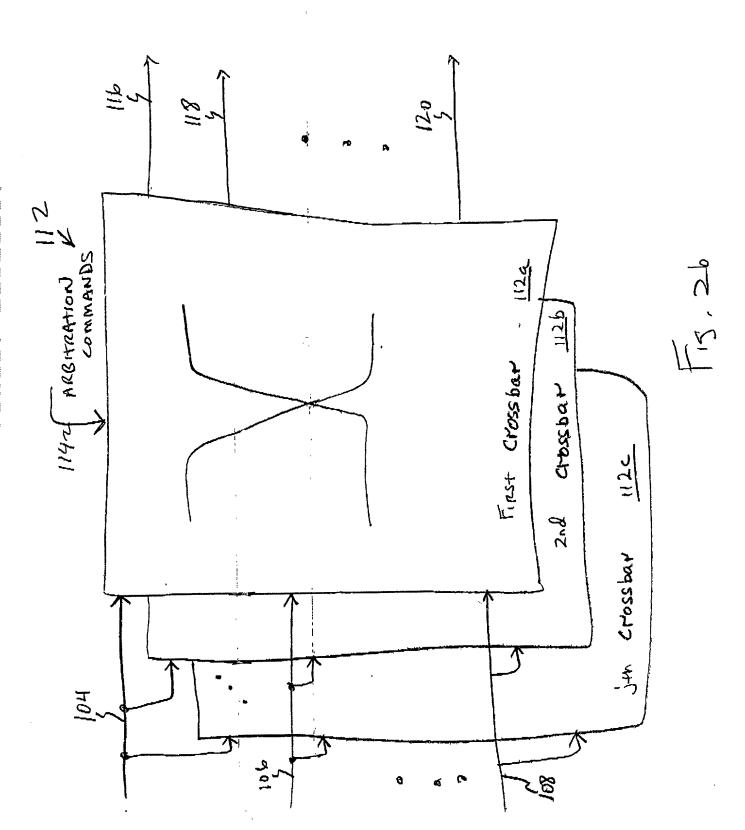


Fig. 2a

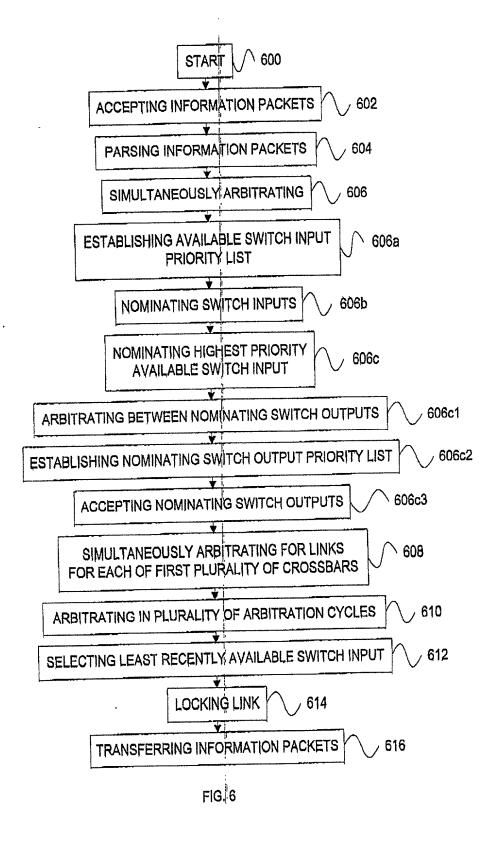


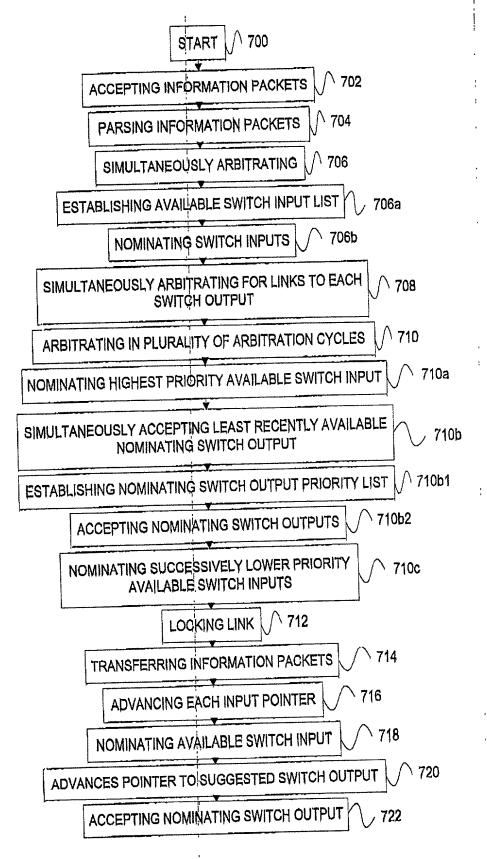
Jth XBAR 15t INPUT 2nd INPUT 1 1 1 1 1 1 1 1 1 1 1 1 1 1 1 1 1 1 1	Svd Input Svd Input And Input in in Put	F19.36
2nd KBAR 2nd KBAR 1st input 2nd INPUT inth input	SAL SAPOT SAL SAPOT ATA IAPUT SAL SAPOT	PRIORITY GISTS
15t ARBITRATION 15t INPUT 2nd INPUT 1 1 1 1 1 1 1 1 1 1 1 1 1 1 1 1 1 1 1	and input The input	sw Infor
1st State State Ist 2nd input 32-3 17th input	2ng 2nd 1npor 134 y man 1 npor 1 136 y not 1 npor 1 136 y not 1 no	AURICA BLE

2nd ARBITRATION CYCIP BAR BAR 2nd IMPORT	Inth into	nth weut
2nd KBAR 2nd MRVT	nth input	nth INPUT
IST INPOT ST 2nd INPUT SUTPUT 132 - MTh (NPUT)	2-nd 2-nd 1ndut Output 1347 nth (Nout)	nth outbut input input input input in input inpu

F19, 3c

F13. 3d





FIG, 7

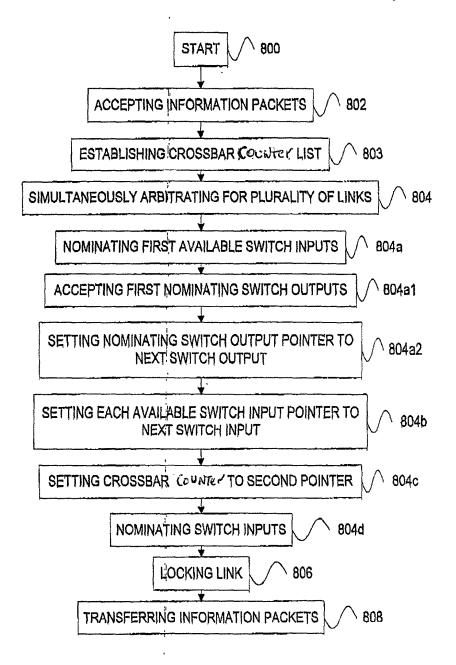


FIG. 8

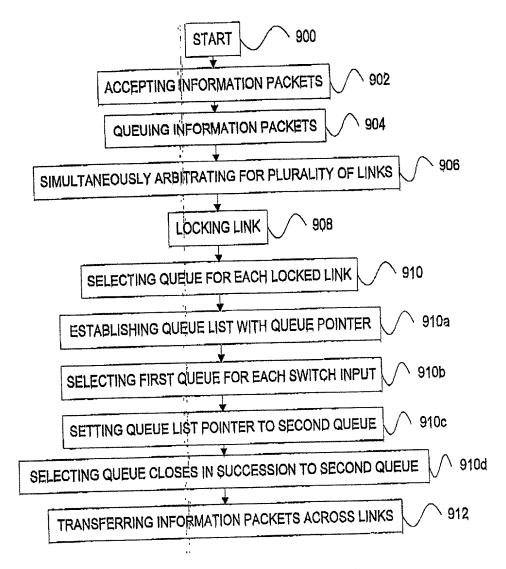


FIG. 9

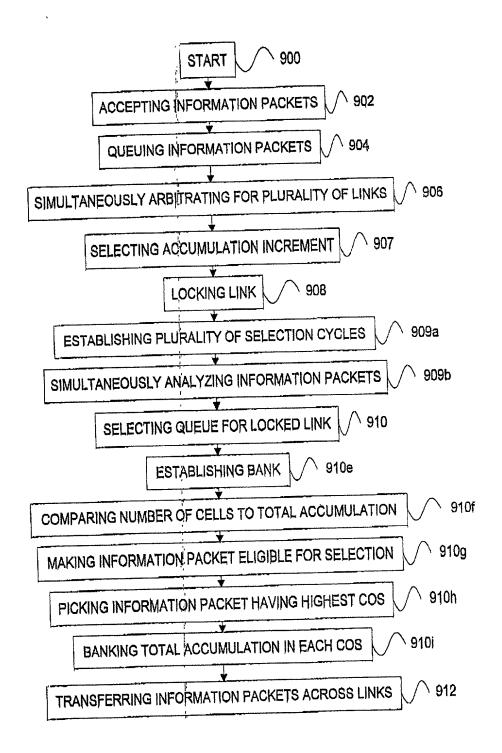


FIG. 10